

IN THE SPECIFICATION:

Please AMEND the specification at page 13, lines 5-10, as follows:

-- Then, the a pin 43 is inserted into the pin connection hole 30b1 and 30b1 of the elevating member 30 and the pin hole 31a of the arm member 31, under the condition the base end of the arm member 31 is inserted into the space Q of the elevating member 30. Thereby, the arm member 31 ~~rotatably~~rotatably connects with the elevating member 30.

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Please AMEND the specification at page 13, lines 11-16, as follows:

-- Additionally, a pin 44 is inserted into the pin hole 31b of the arm member 31 and the pin connection hole 50a1 and 50a1 of the connection section 50a and 50a, under the condition the tip of the arm member 31 is inserted between the connection sections 50a and 50a of the finger link F1. Thereby, the arm member 31 is ~~rotatably~~rotatably connects with the finger link F1. --

Please AMEND the specification at page 13, lines 17-24, as follows:

-- Furthermore, a connection pin 45 is inserted into the connection hole 50a2 and 50a2 one of them is not shown of the connection section 50a and 50a and connection hole 13a and 14a of the guide plate 13 and 14, under the condition the connection section 50a and 50a of the finger link F1 is inserted between the guide plates 13 and 14 of the first link 10. Thereby, the finger link F1 ~~is-rotatably~~ connects with the first link 10. --

Please AMEND the specification at page 15, lines 8-15, as follows:

-- As shown in FIG.5A, the finger link F1 is flexed in compliance with the flexing of the first link 10. Additionally, due to the flexing of the first link 10, the elevating member 30 sandwiched between guide plates 13 and 14 turns in a clockwise direction around the control axis 42, which serves as the supporting point, together with the first link 10, and ~~thus~~ the elevating member 30 is positioned at the end (rigid axis 40 side) of the guide plate 13 and 14. --

Please AMEND the specification at page 15, lines 16-19, as follows:

-- In the condition of posture A of FIG.5A and FIG.6A, the connection link 22 ~~begins~~begin to rotate in a clockwise direction with respect to the rotator 21 around the link axis 41, when the rotator 21 is rotated in an anti-clockwise direction. --

Please AMEND the specification at page 16, lines 13-19, as follows:

-- Next, in posture B of FIG.5B and FIG.6B, the bearing 60 provided on the control axis 42 slides upward due to a torque of the connection link 22, when the rotator 21 is still rotated to an anti clockwise direction. Then, the control axis 42 ~~comes~~come in contact with the tip of the guide long hole 11b and thus the posture is changed to the posture B shown in FIG.5C and FIG. 6C. --

Please AMEND the specification at page, 16, line 20, to page 17, line 3, as follows:

-- In this occasion, since the second guide hole 2b2 is formed along a direction separating from the rigid axis 40, the position within the guide long hole 11b of the control axis 42 changes so that the control axis 42 gradually separate from the rigid axis 40. That is, in the posture B, since the direction of the second guide hole 2b2 and the direction of the guide long hole 11b agree with each other, further rotation of the first link 10 leg 11 in an anti clockwise direction is forbidden. Thus, the elevating member 30 connected to the connection link 22 is lifted under the guide of the guide plate 13 and 14.

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Please AMEND the specification at page 17, lines 4-10, as follows:

-- In this occasion, as shown in FIG.7, the arm member 31 disposed on the elevating member 30 is pushed upward, and thus the finger link F1 is ~~pushed~~pushes upward through the supporting point disposed inside with respect to the connection pin 45. Thus, the finger link F1 is rotated to an outside around the connection pin 45 which serves as the supporting point. That is, the finger link F1 rotates around the second axis S2. --

Please AMEND the specification at page 19, line 22, to page 20, line 4, as follows:

-- As for both embodiments shown in FIG.8A and FIG.8B, the finger link F1 is rotated around the connection hole 50a2 (the second axis S2), which serves as a supporting point, by the up-and-down directional~~ups and downs direction's~~ movement of the control axis 42 that is caused in accordance with the actuation of the connection link 22 (not shown). By directly actuating the finger link F1 by the control axis 42, the omission of the elevating member 30 and the arm member 31 is enabled. Thereby, further reducing of the number of the parts can be enabled. --

Please AMEND the specification at page 20, lines 5-8, as follows:

-- FIG.9 is a schematic view showing robot hand apparatus 1A, in which the second ~~linking~~ is simplified. FIG.9A indicates the motion around a first axis, and FIG.9B indicates the motion around a second axis. --

Please AMEND the specification at page 20, line 25, to page 21, line 3, as follows:

-- In the robot hand apparatus 1A, as shown in FIG.9A, since second link 20A rotates in an anti clockwise direction by the torque of the actuation shaft g, the control axis 42A moves within the long guide hole 11c of the first link 10A ~~from~~from one end to the other end. --